This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1 (withdrawn): The method of transmitting 2D images and depth map data for viewing on a stereoscopic viewing system according to claim 4, wherein:

the depth map data is embedded in a vertical blanking interval of an analog television signal.

2 (previously presented): The method according to claim 4, wherein

the depth map data is embedded in an MPEG data stream of a digital television signal.

3 (withdrawn): The method of transmitting 2D images and depth map data for viewing on a stereoscopic viewing system according to claim 4, wherein

embedding the depth map data in a VOB file of a DVD.

4 (currently amended): A method comprising:

receiving, from an external source, 2D images and depth map data of a depth map relating to the 2D images;

responsive to the receiving of the 2D images and depth map data from the external source, embedding the depth map data in a portion of a video signal including the 2D image data which does not obscure or overwrite the 2D image data, and without loss of fidelity in a relative range of values in the depth map; and

transmitting the video signal, wherein the transmitted video signal is configured to convert the 2D images for viewing in a stereoscopic viewing system.

5 (new): The method of claim 4, wherein the external source is a remote source.

6 (new): A method comprising:

receiving 2D images and depth map data of a depth map relating to the 2D images;

responsive to the receiving, embedding the depth map data in a portion of a video signal including the 2D image data which does not obscure or overwrite the 2D image data, and without loss of fidelity in a relative range of values in the depth map; and

transmitting the video signal, wherein the transmitted video signal is configured to convert the 2D images for viewing in a stereoscopic viewing system,

wherein the depth map is produced by:

identifying at least one object within the 2D image without using distance measurement data;

allocating an identifying tag to the at least one object;

allocating a depth tag to the at least one object;

determining and defining an outline for the at least one object; and

encoding the identifying tag, the depth tag and the outline, of the at least one object to produce the depth map.